



**APRIL 16TH 2025, H. 12:00**  
**SEMINAR ROOM, POLO FERRARI 2 - VIA SOMMARIVE 9, TRENTO**

The past few years have witnessed significant progress in the field of legged locomotion and manipulation. This is mainly due to the availability of high-performance hardware as well as development of algorithms that scale to high-dimensional, hybrid and under-actuated systems. In this talk, I will present my recent research efforts, mainly on the algorithmic side, on developing efficient predictive controllers that can be complemented with supervised/reinforcement learning for real-time execution on loco-manipulation systems. I will also share my perspective on the open problems that we still need to solve to have functional humanoid robots in the real world.

**Speaker: Prof. Majid Khadiv**  
**School of Computation, Information and Technology (CIT)**  
**Technische Universität München (TUM)**

# Predictive control and learning for loco-manipulation

**DII SEMINAR**

